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Park et al.

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(54) **ACTUATION CONTROL SYSTEM OF A CAPSULE ENDOSCOPE**

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(*) Notice: Subject to any disclaimer, the term of this patent is extended or adjusted under 35 U.S.C. 154(b) by 0 days.

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(21) Appl. No.: **13/446,107**

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(65) **Prior Publication Data**

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(30) **Foreign Application Priority Data**

Aug. 31, 2011 (KR) 10-2011-0087838

(57) **ABSTRACT**

(51) **Int. Cl.**
A61B 1/04 (2006.01)
A61B 1/00 (2006.01)

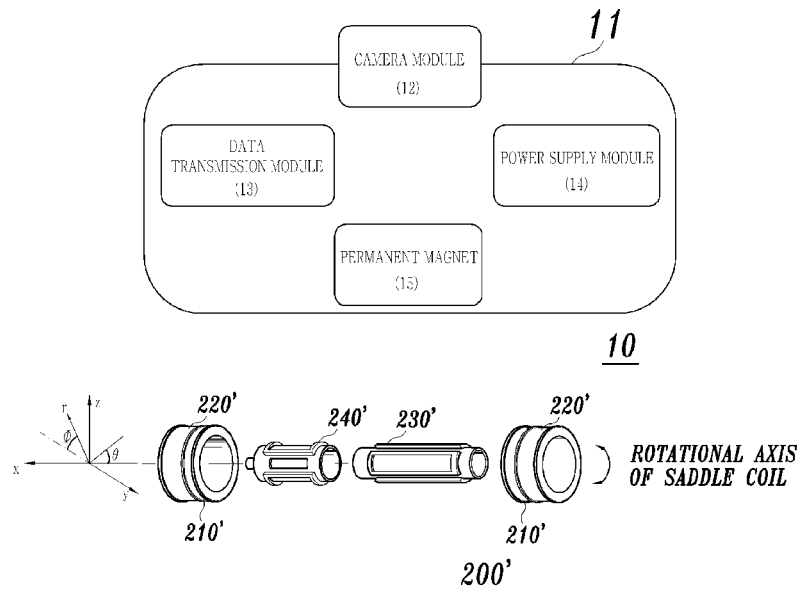
A system for controlling actuation of a capsule endoscope includes a receiving unit receiving an image transmitted from the capsule endoscope; a coil unit generating a magnetic field for actuating the capsule endoscope by using current applied thereto; a power supply unit supplying power to the coil unit; and an actuation controller control the current applied to the coil unit and a coil rotational motor for adjusting of a posture and the location of the capsule endoscope based on the identified lesion or location of the capsule endoscope, wherein the coil unit includes a pair of Helmholtz coils and a pair of Maxwell coils that are fixedly disposed on a main axis; and a pair of uniform saddle coils and a pair of gradient saddle coils that are located inside the pair of the Helmholtz coils and the pair of the Maxwell coils to rotate around the main axis.

(52) **U.S. Cl.**
CPC **A61B 1/041** (2013.01); **A61B 1/00158** (2013.01)

(58) **Field of Classification Search**

CPC A61B 1/041; A61B 1/00158
USPC 600/103, 117, 118, 160, 178
See application file for complete search history.

4 Claims, 8 Drawing Sheets



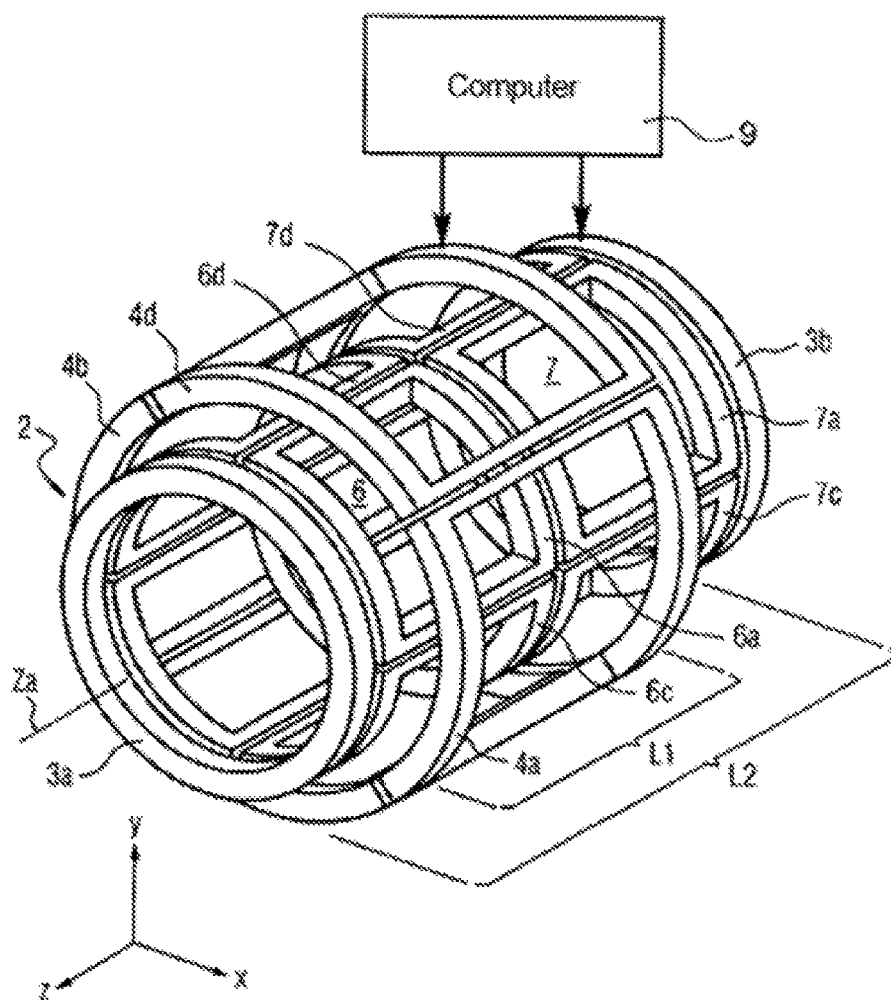


FIG. 1
PRIOR ART

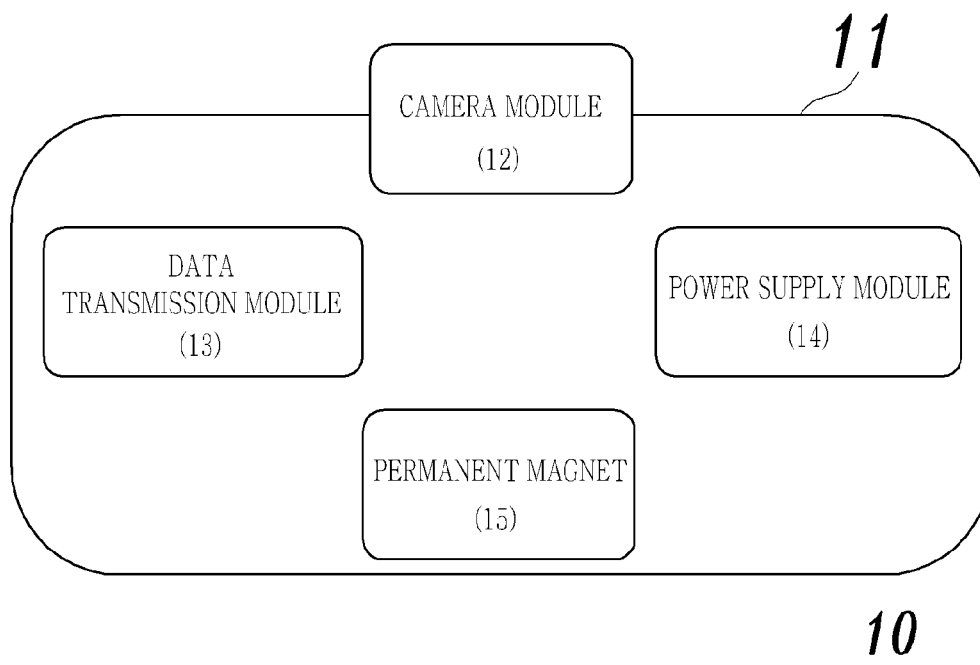
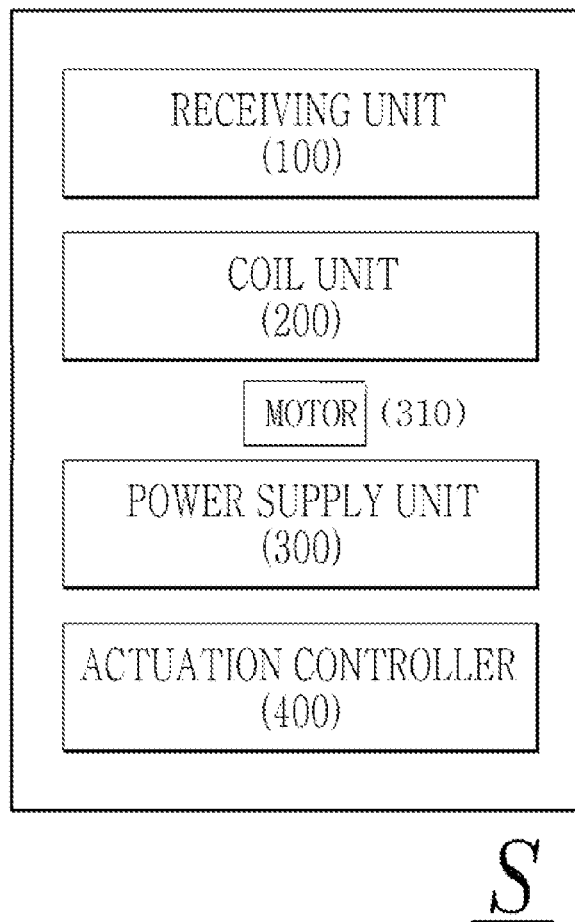


FIG. 2

S**FIG. 3**

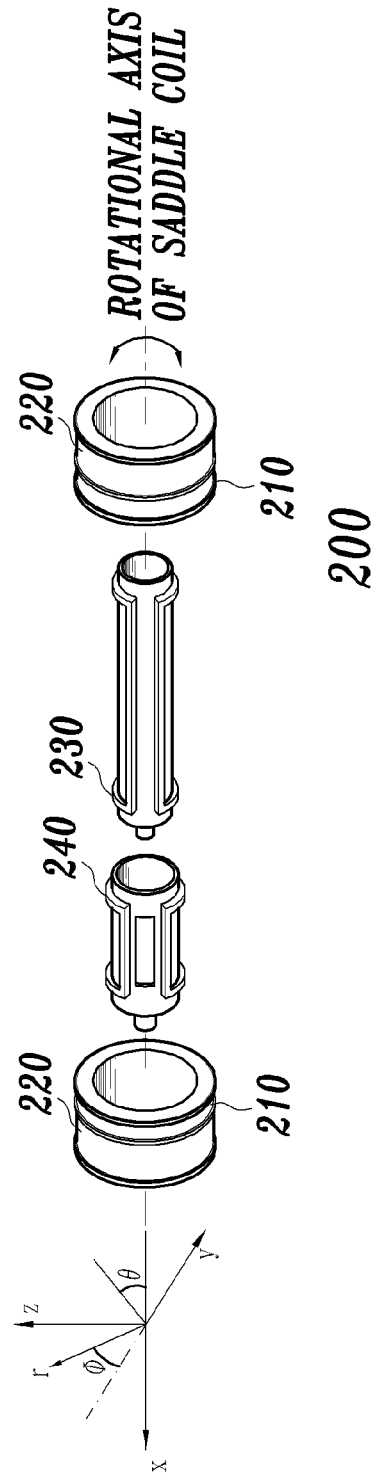


FIG. 4

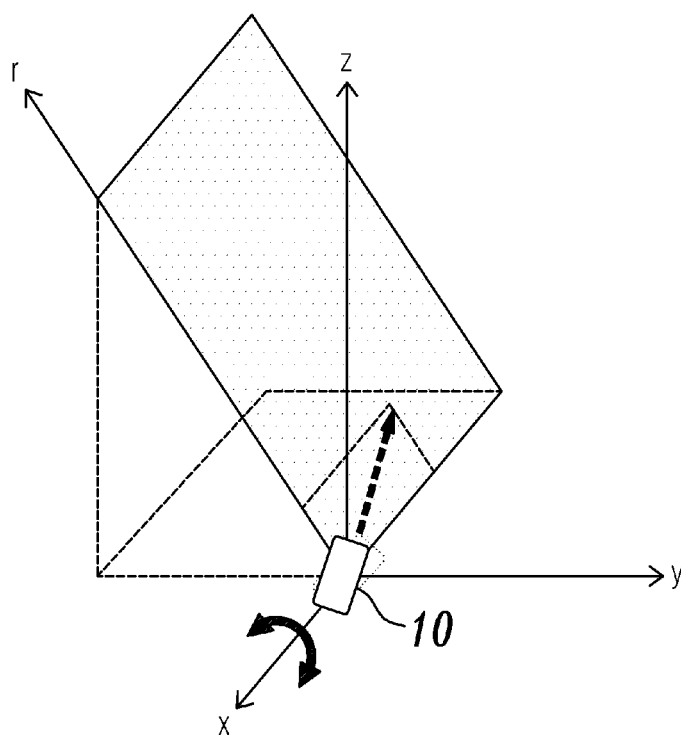


FIG. 5

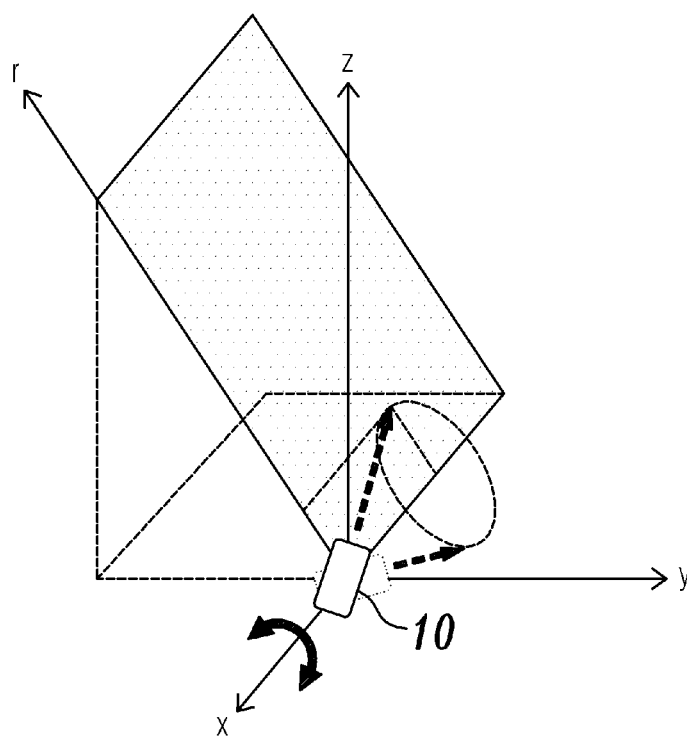


FIG. 6

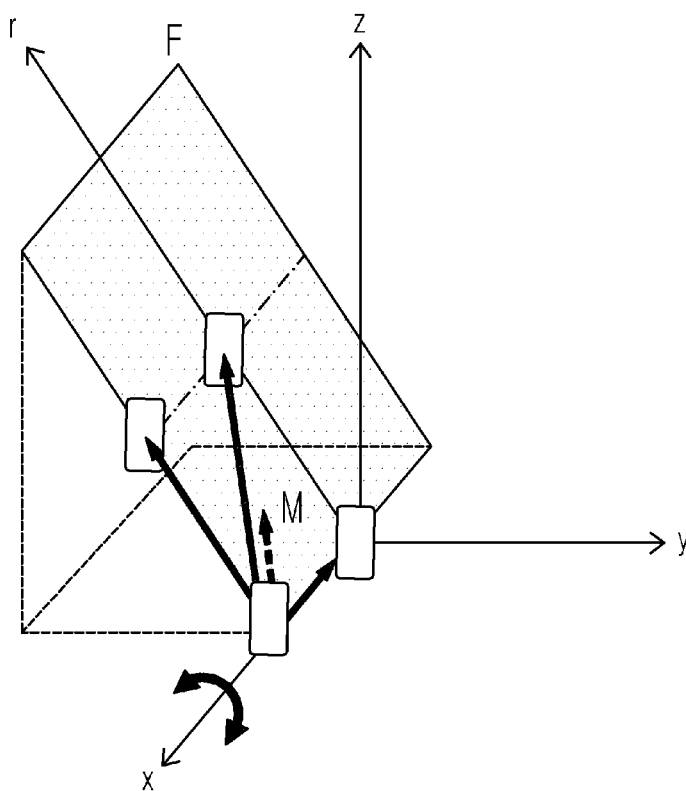


FIG. 7

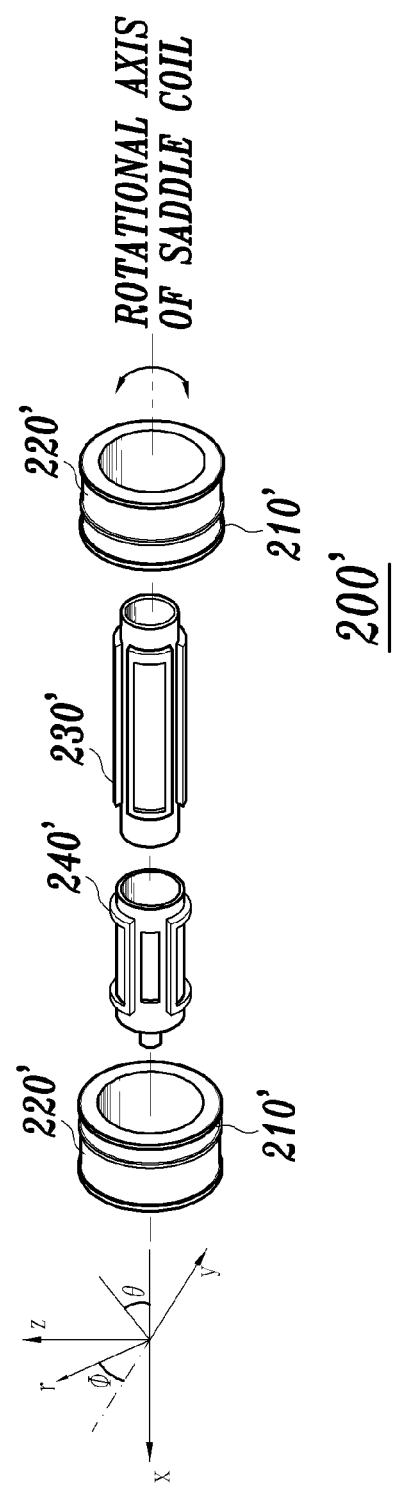


FIG. 8

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ACTUATION CONTROL SYSTEM OF A CAPSULE ENDOSCOPE

PRIORITY

This application claims the benefit under 35 U.S.C. §119 a of a Korean patent application filed in the Korean Intellectual Property Office on Aug. 31, 2011 and assigned Serial No. 10-2011-0087838, and the entire disclosure of which is hereby incorporated by reference.

BACKGROUND OF THE INVENTION

1. Field of the Invention

The present invention relates to an actuation control system of a capsule endoscope, and more particularly, to an actuation control system of a capsule endoscope, which is capable of precisely diagnosing not only a digestive system having a tubular shape such as an esophagus, a small intestine, or a large intestine but also a well of a wide organ such as a stomach and is capable of performing detailed examination of an organ at a desired location.

2. Description of the Related Art

A conventional flexible streamlined endoscope is inserted through a mouth or anus and controlled to perform an examination. To reduce difficulties in handling the endoscope and reduce a patient's suffering, a capsule endoscopic, which is swallowed through the mouth and passes through digestive systems for examination, is developed.

However, this capsule endoscope has a limited size so that various functions may not be performed. Also, because intestinal walls are slippery, the capsule endoscope is actuated in a passive manner such as peristalsis of the intestine.

To improve these disadvantages, a research on an actuation mechanism for actuating the capsule endoscope using an electromagnetic actuation system is conducted.

Meanwhile, in an electromagnetic actuation system for medical devices including the capsule endoscope, only a rotational motion and a straight line motion are enabled. Also, even if a translational motion is enabled, a coil system has a unsuitable coil structure in which a patient could not enter for treatment.

Meanwhile, numerous patent applications and patents, including U.S. Patent Publication No. 2008/0272873 (hereafter, "prior art document"), are related to a coil system for actuating the capsule endoscope.

As shown in FIG. 1, in the coil system for actuating the capsule endoscope disclosed in the prior art document, a total of 18 coils can be used to move the capsule endoscope in a certain direction.

However, the prior art coil system has a problem in that power consumption could be increased to move the capsule endoscope due to a high number of coils and each coil's role is not clearly defined.

SUMMARY OF THE INVENTION

Accordingly, the present invention has been made as a remedy of the above problems, and the present invention is to provide an actuation control system of a capsule endoscope that controls tilting and rotating motions as well as parallel and translational motions of the capsule endoscope, thereby being capable of precisely diagnosing not only a digestive system having a tubular shape such as an esophagus, a small intestine, or a large intestine but also a well of a wide organ such as a stomach and being capable of performing detailed examination of an organ at a desired location.

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In one aspect of the present invention, a system for controlling actuation of a capsule endoscope includes a receiving unit configured to receive an image transmitted from the capsule endoscope; a coil unit configured to generate a magnetic field for actuating the capsule endoscope by using current applied thereto; a power supply unit configured to supply power to the coil unit; and an actuation controller configured to identify lesion or a location of the capsule endoscope based on the image received through the receiving unit and configured to control a motor for controlling the current applied to the coil unit and a posture and the location of the capsule endoscope based on the identified lesion or location of the capsule endoscope, wherein the coil unit comprises a pair of Helmholtz coils and a pair of Maxwell coils that are fixedly disposed on a main axis; and a pair of uniform saddle coils and a pair of gradient saddle coils that are located inside the pair of the Helmholtz coils and the pair of the Maxwell coils to rotate around the main axis.

BRIEF DESCRIPTION OF THE DRAWINGS

The above and other objects, features and advantages of the present invention will be more clearly understood from the following detailed description taken in conjunction with the accompanying drawings, in which:

FIG. 1 is a configuration view illustrating a coil system for actuating a conventional capsule endoscope;

FIG. 2 is a view illustrating a configuration of a capsule endoscope according to the present invention;

FIG. 3 is a view illustrating an entire configuration of a capsule endoscope actuating control system according to the present invention;

FIG. 4 is a view illustrating a configuration of a coil unit according to the present invention;

FIG. 5 is a view illustrating an exemplary embodiment of controlling a capsule endoscope to perform a tilting motion according to the present invention;

FIG. 6 is a view illustrating an exemplary embodiment of controlling a capsule endoscope to rotate around a certain axis according to the present invention;

FIG. 7 is a view illustrating an exemplary embodiment of controlling a capsule endoscope to perform a parallel motion and a translational motion according to the present invention; and

FIG. 8 is a view illustrating a configuration of a coil unit according to another exemplary embodiment of the present invention.

DETAILED DESCRIPTION OF THE INVENTION

The features and advantages of the present invention will be more apparent from the following detailed description in view of the accompanying drawings. In the following description of the present invention, a detailed description of known functions and configurations incorporated herein will be omitted so as not to obscure the subject matter of the present invention.

The present invention now will be described more fully hereinafter with reference to the accompanying drawings.

With reference to FIG. 2 or FIG. 8, an actuation control system of a capsule endoscope according to the present invention is described.

First, a capsule endoscope 10 that is driven by a capsule endoscope actuation control system (S) according to the present invention is described.

As shown in FIG. 2, the capsule endoscope 10 includes a capsule-shaped housing 11, a camera module 12, a data trans-

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mission module **13**, a power supply module **14**, and a permanent magnet **15** installed within the housing **11**.

Specifically, the data transmission module **12** may be fixedly installed on a front or rear surface or a wall of the housing **11** along a longitudinal direction of the housing **11**.

The data transmission module **13** transmits images obtained through the camera module **12** to outside.

The power supply module **14** supplies operational power to the camera module **12** and the data transmission module **13** and may use a battery.

The permanent magnet **15** may be magnetized in a certain direction within the housing **11** for electromagnetic actuation, and the capsule endoscope **10** may be driven by a magnetic field generated by an electromagnetic actuator coil.

As shown in FIG. 3, the capsule endoscope actuation control system **S** includes a receiving unit **100**, a coil unit **200**, a power supply unit **300**, and an actuation controller **400**.

The receiving unit **100** receives images transmitted from the capsule endoscope **10**.

The coil unit **200** generates a magnetic field for actuating the capsule endoscope **10** by using a current applied thereto.

Specifically, as shown in FIG. 4, the coil unit **200** includes a pair of Helmholtz coils **210** and a pair of Maxwell coils **220** that are fixedly disposed on a main axis (or x axis) and a pair of uniform saddle coils **230** and a pair of gradient saddle coils **240** that are located inside the pair of the Helmholtz coils **210** and the pair of the Maxwell coils **220** to rotate around the main axis (or x axis).

The power supply unit **300** supplies power to the coil unit **200**.

The actuation controller **400** identifies lesion or a location of the capsule endoscope **10** based on the images received through the receiving unit **100** and controls the currents to be applied to the coil unit **200** and a coil rotational motor (**310**) for adjusting of a posture and the location of the capsule endoscope **10**.

FIG. 5 is a view illustrating an exemplary embodiment of controlling the capsule endoscope **10** to perform a tilting motion according to the present invention.

As shown in FIG. 5, in order for the capsule endoscope **10** to perform a tilting motion in a certain direction on a plane (or an x-r plane) that is tilted at a certain angle relative to the x axis, the actuation controller **400** adjusts strength of magnetic fields of the pair of the Helmholtz coils **210** and the pair of the uniform saddle coils **230** while the pair of the uniform saddle coils **230** and the pair of the gradient saddle coils **240** coincide with an r axis, thereby realizing the tilting motion of the capsule endoscope **10** at a certain angle.

FIG. 6 is a view illustrating an exemplary embodiment of controlling the capsule endoscope **10** to rotate around a certain axis according to the present invention.

As shown in FIG. 6, in order for the capsule endoscope **10** to rotate around a certain axis on the plane (or the x-r plane) that is tilted at a certain angle relative to the x axis, the actuation controller **400** adjusts strength of magnetic fields generated by the pair of the Helmholtz coils **210** and the pair of the uniform saddle coils **230** and rotation the generated magnetic fields while the pair of the uniform saddle coils **230** and the pair of the gradient saddle coils **240** coincide with the r axis, thereby realizing a rotational motion of the capsule endoscope **10** around a certain axis.

FIG. 7 is a view illustrating an exemplary embodiment of controlling the capsule endoscope **10** to perform a parallel motion and a translational motion according to the present invention.

As shown in FIG. 7, in order for the capsule endoscope **10** to perform a parallel motion and a translational motion on the

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plane (or the x-r plane) that is tilted at a certain angle relative to the x axis, the actuation controller **400** adjusts strength of the magnetic fields of the pair of the Helmholtz coils **210** and the pair of the uniform saddle coils **230** to be aligned in a certain direction while the pair of the uniform saddle coils **230** and the pair of the gradient saddle coils **240** coincide with the r axis. Accordingly, a gradient of the magnetic fields generated by the pair of the Maxwell coils **220** and the pair of the gradient saddle coils **240** is adjusted, thereby generating a driving force of the capsule endoscope **10** in a desired direction.

FIG. 8 is a view illustrating a configuration of a coil unit **200'** according to another exemplary embodiment of the present invention. As shown in FIG. 8, the coil unit **200'** includes a pair of Helmholtz coils **210'** and a pair of Maxwell coils **220'** that are fixedly disposed on a main axis (or x axis) and two pairs of uniform saddle coils **230'** and a pair of gradient saddle coils **240'** that are located inside the pair of the Helmholtz coils **210'** and the pair of the Maxwell coils **220'**, wherein the two pairs of the uniform saddle coils **230'** are placed on a plane that is perpendicular to the main axis (or x axis), the two pairs of the uniform saddle coils **230'** being fixedly disposed on the plane to be perpendicular to each other, and the pair of the gradient saddle coils **240'** are disposed to rotate around the main axis (x axis).

A method of controlling the capsule endoscope **10** to realize the tilting motion by using the capsule endoscope actuation control system **S** including the coil unit **200'** according to another exemplary embodiment of the present invention is described.

In order for the capsule endoscope **10** to realize a tilting motion in a certain direction on a plane (or the x-r plane) that is tilted at a certain angle relative to the x axis, the actuation controller **400** adjusts strength and direction of magnetic fields of the pair of the Helmholtz coils **210'** and the two pairs of the uniform saddle coils **230'**, thereby realizing the tilting motion of the capsule endoscope **10** at a certain angle.

Also, a method of controlling the capsule endoscope **10** to rotate around a certain axis by using the capsule endoscope actuation control system **S** including the coil unit **200'** according to another exemplary embodiment of the present invention is described.

In order for the capsule endoscope **10** to rotate around a certain axis on the plane (or the x-r plane) that is tilted at a certain angle relative to the x axis, the actuation controller **400** adjusts strength and direction of the magnetic fields generated by the pair of the Helmholtz coils **210'** and the two pairs of the uniform saddle coils **230'**, thereby realizing a rotational motion of the capsule endoscope **10** around a certain axis.

Further, a method of controlling the capsule endoscope **10** to realize a parallel motion and a translational motion by using the capsule endoscope actuation control system **S** including the coil unit **200'** according to another exemplary embodiment of the present invention is described.

In order for the capsule endoscope **10** to realize the parallel motion or the translational motion on the plane (or the x-r plane) that is tilted at a certain angle relative to the x axis, the actuation controller **400** adjusts strength and direction of the magnetic fields of the pair of the Helmholtz coils **210'** and the two pairs of the uniform saddle coils **230'** while the pair of the gradient saddle coils **240'** coincide with the r axis to be aligned in a certain direction. Accordingly, a gradient of the magnetic fields generated by the pair of the Maxwell coils **220'** and the pair of the gradient saddle coils **240'** is adjusted, thereby generating a driving force of the capsule endoscope **10** in a desired direction.

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According to the present invention described above, tilting and rotating motions as well as parallel and translational motions of the capsule endoscope can be controlled so that the present invention can apply not only to the capsule endoscope capable of observing digestive systems such as esophagus, small intestine, or large intestine, but also to various medical fields for minimally invasive surgery such as a micro robot capable of moving inside blood vessels to treat disease or a micro robot capable of moving inside a spinal canal.

In the above, although the embodiments of the present invention have been described with reference to the accompanying drawings, a person skilled in the art should apprehend that the present invention can be embodied in other specific forms without departing from the technical spirit or essential characteristics thereof. Thus, the embodiments described above should be construed as exemplary in every aspect and not limiting.

What is claimed is:

1. A system for controlling actuation of a capsule endoscope, the system comprising:

- a receiving unit receiving images transmitted from the capsule endoscope;
- a coil unit generating a magnetic field for actuating the capsule endoscope by using applied current thereto;
- a power supply unit supplying power to the coil unit; and
- an actuation controller identifying lesion or a location of the capsule endoscope based on the images received through the receiving unit and controlling a motor for controlling the current applied to the coil unit and a posture and the location of the capsule endoscope based on the identified lesion or location of the capsule endoscope,

wherein the coil unit comprises

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a pair of Helmholtz coils fixedly disposed on a main axis,

a pair of Maxwell coils fixedly disposed on the main axis,

two pairs of uniform saddle coils located inside the pair of the Helmholtz coils and the pair of the Maxwell coils and fixedly disposed on a plane perpendicular to the main axis, the two pairs of the uniform saddle coils being disposed to be orthogonal to each other and not rotating about the main axis, and

a pair of gradient saddle coils disposed inside the pair of the Helmholtz coils and the pair of the Maxwell coils and rotating about the main axis.

2. The system according to claim 1, wherein the actuation controller adjusts strength and a direction of magnetic fields of the pair of the Helmholtz coils and the two pairs of the uniform saddle coils such that the capsule endoscope performs a tilting motion at a certain angle.

3. The system according to claim 1, wherein the actuation controller adjusts strength and a direction of magnetic fields generated by the pair of the Helmholtz coils and the two pairs of the uniform saddle coils such that the capsule endoscope performs a rotational motion around a certain axis.

4. The system according to claim 1, wherein the actuation controller adjusts strength and a direction of magnetic fields of the pair of the Helmholtz coils and the two pairs of the uniform saddle coils to be aligned in a certain direction while the pair of the gradient saddle coils coincide with an r axis, such that a gradient of magnetic fields generated by the pair of the Maxwell coils and the pair of the gradient saddle coils are adjusted to generate a driving force of the capsule endoscope in a desired direction.

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